Calibration results
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Camera-system parameters:
cam0 (/oak_d_lite/left/image_mono/compressed):
 type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
 distortion: [0.3595682 0.27994526 -0.00557285 0.00558908] +- [0.00579219 0.0192589 0.00053529 0.00080143]
 projection: [596.73758267 597.07783772 329.30725791 237.31223321] +- [0.2537241 0.255845   0.40914546
 0.30990226]
 reprojection error: [-0.000041, 0.000011] +- [0.146781, 0.130752]

cam1 (/oak_d_lite/right/image_mono/compressed):
 type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
 distortion: [0.35533974 0.33185241 -0.00031782 0.00127538] +- [0.005453   0.0166728 0.00052176 0.00084635]
 projection: [592.37607116 592.89967419 311.10959872 244.76674248] +- [0.24780556 0.26182416 0.47130343
 0.31327565]
 reprojection error: [-0.000043, 0.000005] +- [0.171208, 0.130192]

baseline T_1_0:
 q: [-0.00043199 0.00329359 0.00208351 0.99999231] +- [0.00104915 0.00149079 0.00010347]
 t: [-0.07450866 -0.00027775 -0.00085516] +- [0.00036763 0.00039909 0.00137968]

Target configuration
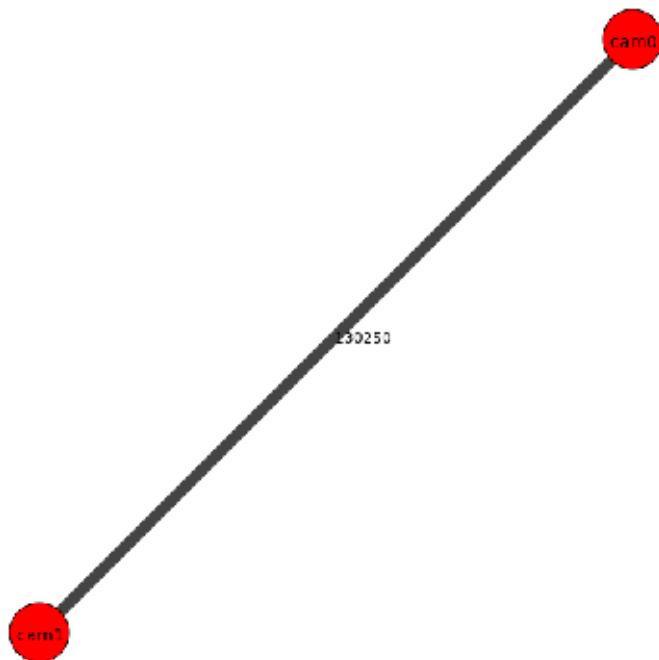====================
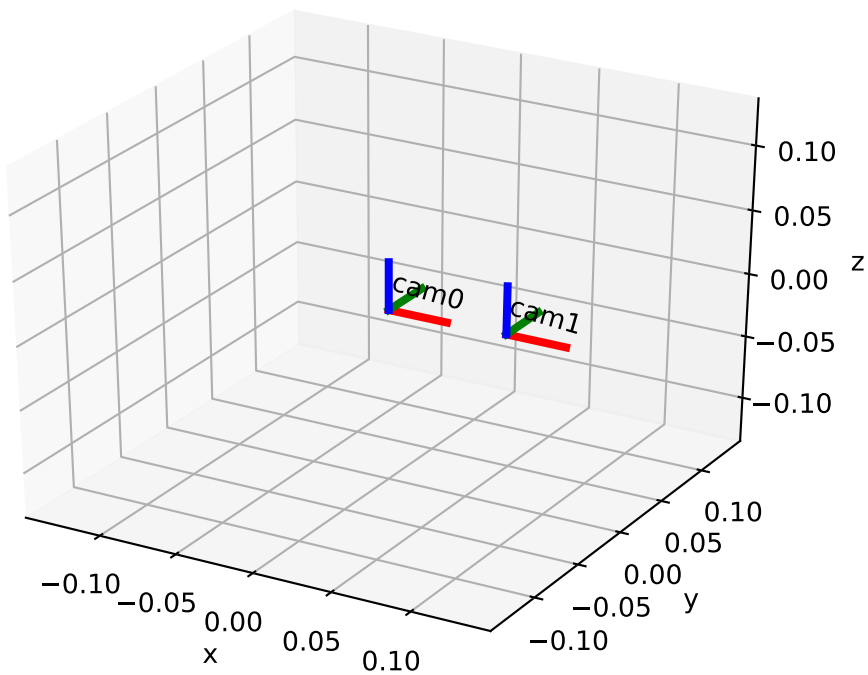
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.088 [m]
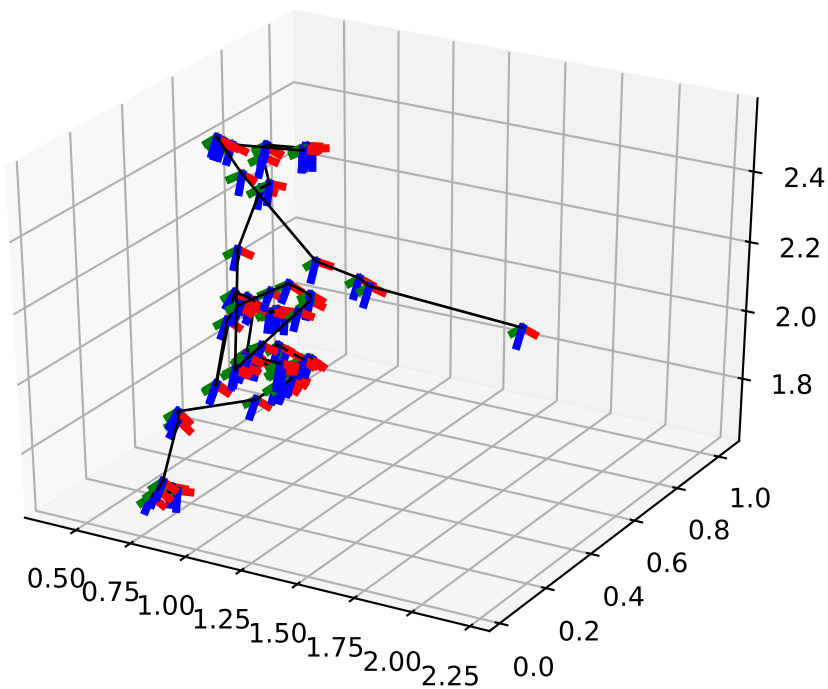Spacing 0.026399999999999996 [m]

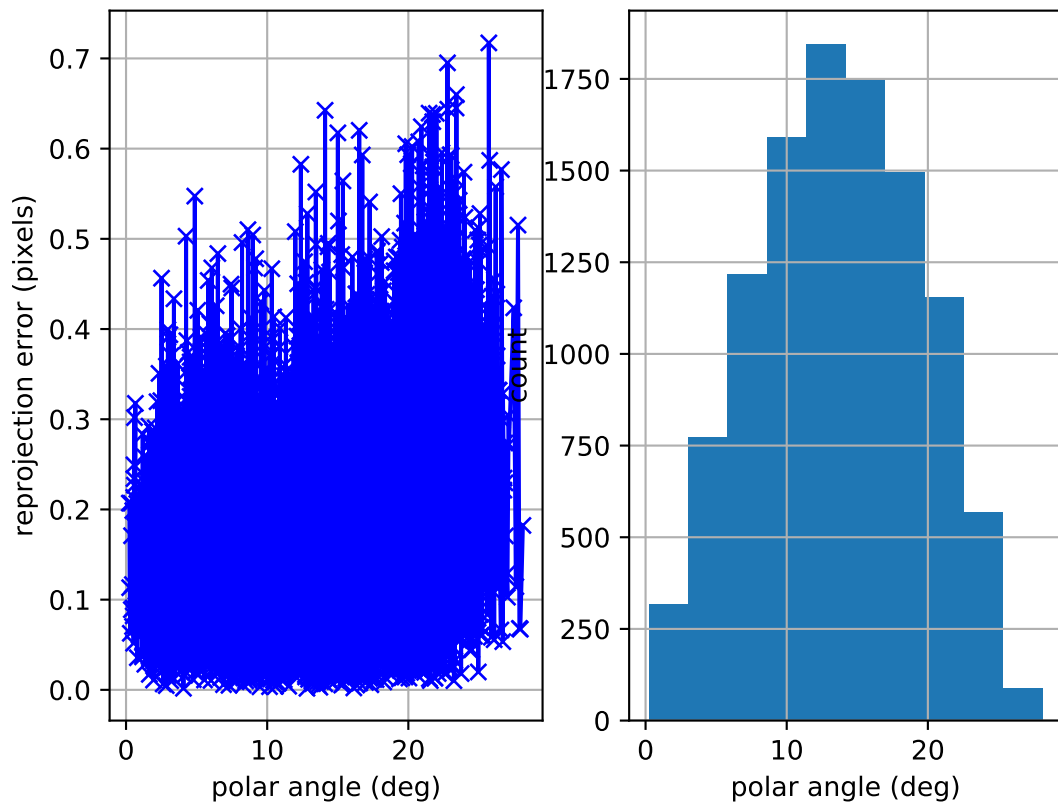# Inter-camera observations graph (edge weight=#mutual obs.)
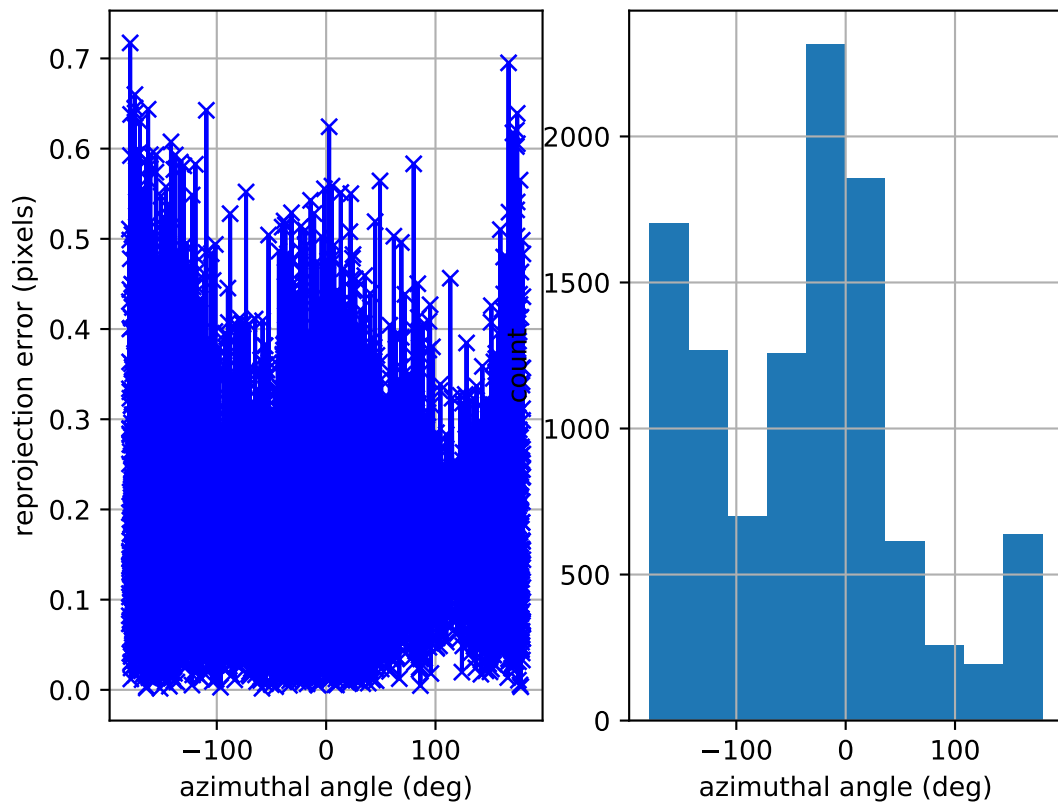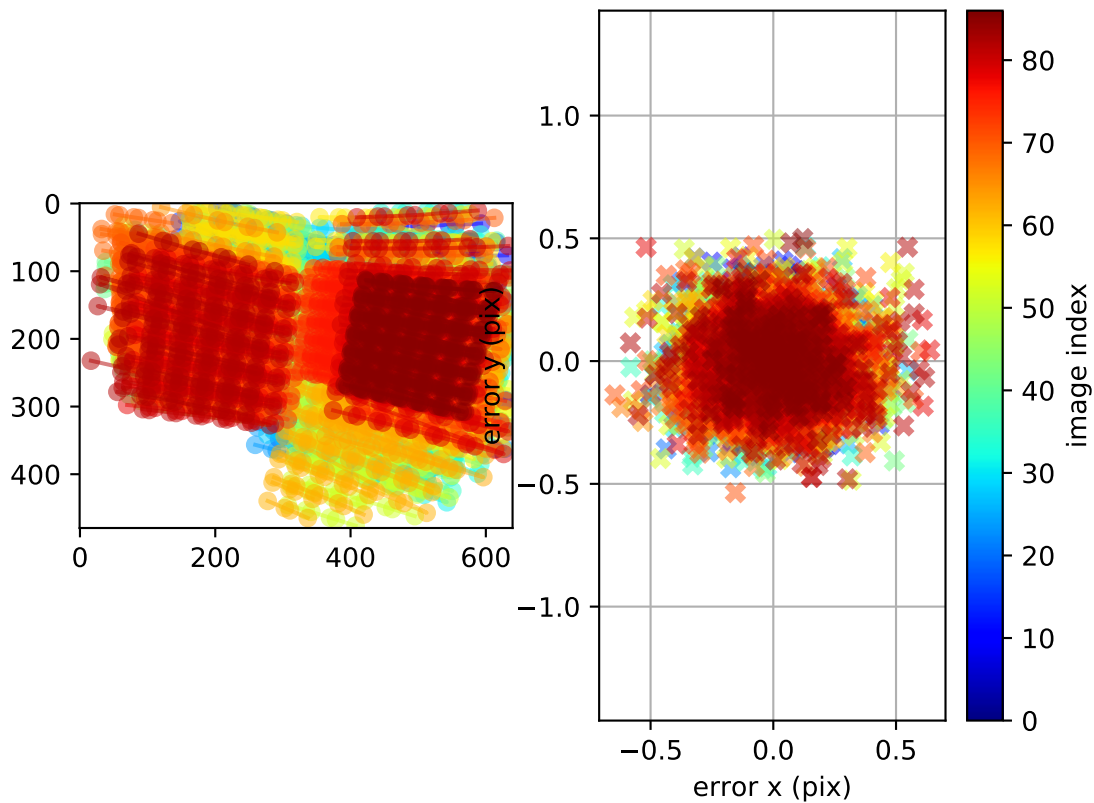
camera system
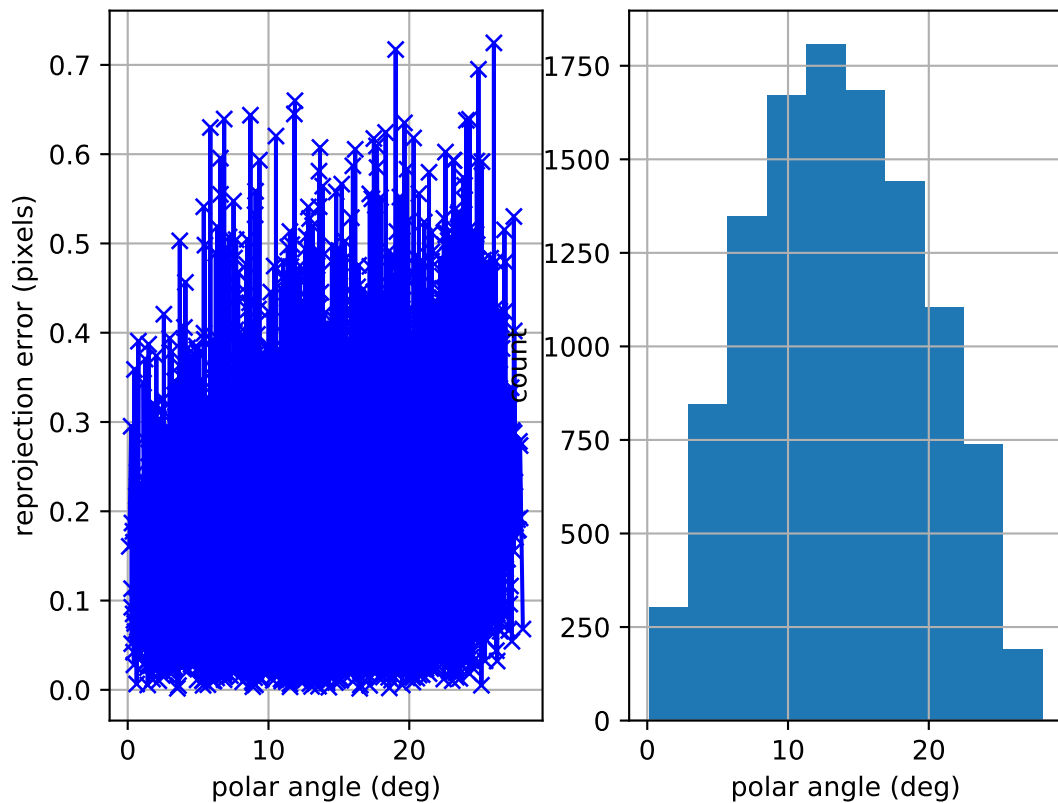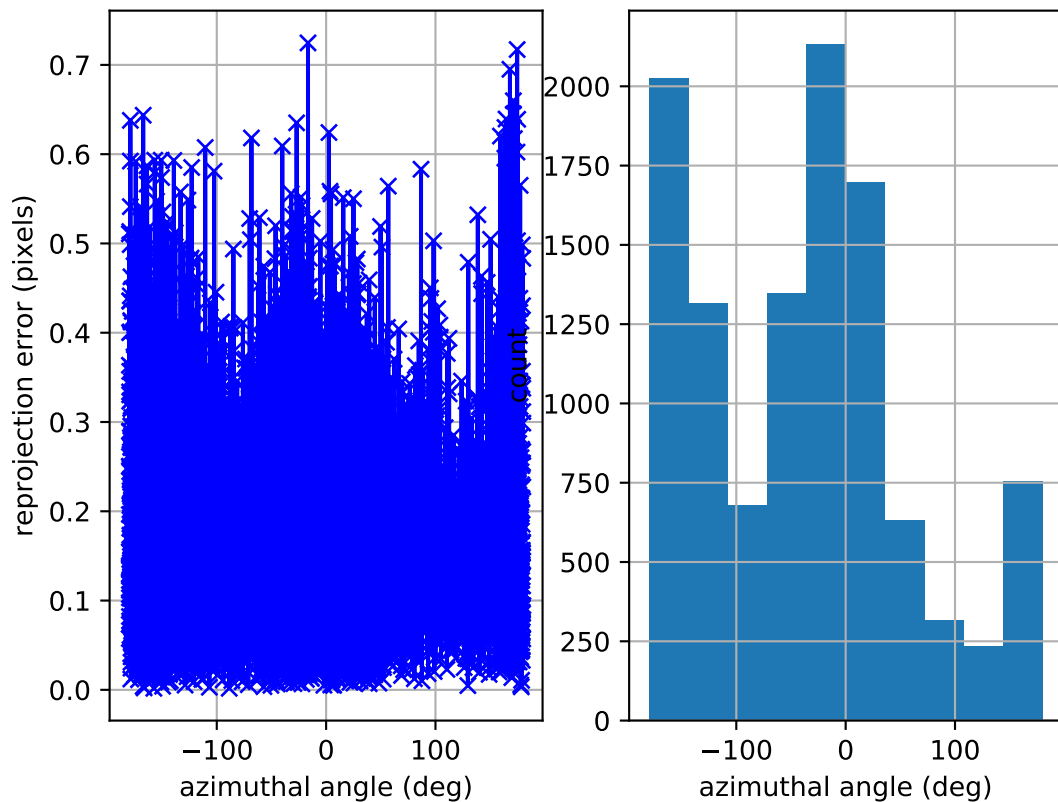
cam0: estimated poses

cam0: polar error

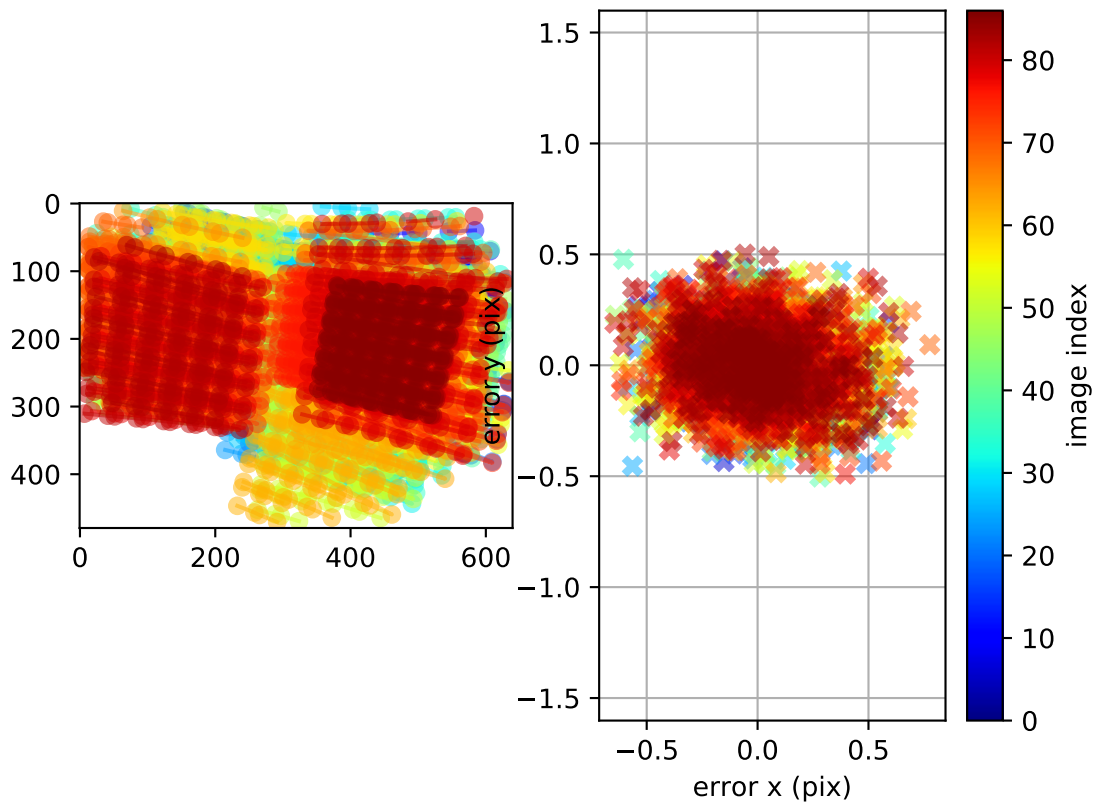cam0: azimuthal error

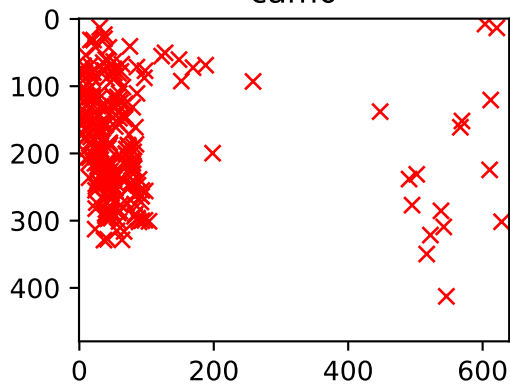cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners